

Experimental Evaluation of Control Policies for Segway Robot in Dynamic Environments

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ECE 6552: Nonlinear System Project

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- ▶ A hybrid approach applies the benefits and mitigates the shortcomings of both
- ▶ A nonlinear navigation control protocol can achieve navigational objectives while reacting to unexpected obstacles

Robotic Platform



Figure : Jeeves - A modified Segway based robot mounted with a Primesense, Microsoft Kinect, Roboteye RE05, Hokuyo LTM-30x laser and the UR5. Currently modified to include the casters for static stability

Unicycle Dynamics

$$\begin{pmatrix} \dot{r} \\ \dot{\theta} \end{pmatrix} = \begin{pmatrix} -v \cos(\delta) \\ \frac{v}{r} \sin(\delta) \end{pmatrix} \quad (1)$$

$$\dot{\delta} = \frac{v}{r} \sin(\delta) + \omega \quad (2)$$

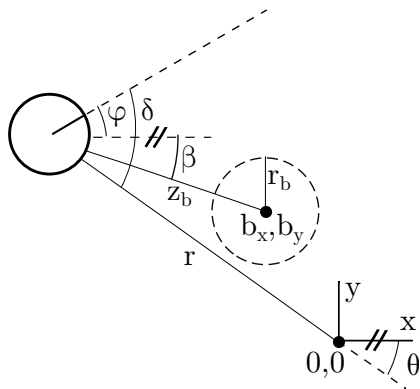


Figure : Egocentric Polar Unicycle Dynamics with Obstacle

Objectives

Soft Constraints

- ▶ Navigate to target location
- ▶ Drive the state of the robot to zero (e.g. $\dot{x} = (\dot{r}, \dot{\theta}, \dot{\delta})^T \rightarrow 0$)

Hard Constraints

- ▶ Avoid obstacles
- ▶ The distance to the obstacle must not exceed a minimum distance (e.g. $z_b > z_{safe}$)

System Constraints

- ▶ Inputs should not exceed threshold values
- ▶ $0 < v < v_{max}$ and $0 < \omega < \omega_{max}$

Approach Overview

A **switched mode** *quadratic programming controller* that **simultaneously** satisfies the soft constraints, hard constraints, and system constraints was designed.

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Feedback linearization of this objective by choosing the angular velocity:

$$\omega = -\frac{v}{r} \left[k_2 z_1 + \left(1 + \frac{k_1}{1 + (k_1\theta)^2}\right) \sin(z_1 + \arctan(-k_1\theta)) \right]$$

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$$\dot{z}_1 = -k_2 \frac{v}{r} z_1$$

\implies *Stabilization of the steering objective*

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$$\dot{V} < 0$$

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$$\dot{V} = -rv \cos(\arctan(k_1\beta)) + \theta v \sin(\arctan(-k_1\beta))$$

$$\dot{V} \not\leq 0$$

\implies *The second steering control drives the state **away** from zero*

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$$\dot{h}(x) =$$

Switched Mode QP Controller

Simulation Results

needs octo plots!

Experimental Results

needs robots!

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Questions?